

If an actuator set to F (forward direction) is in position 4 and the command is sent to go to position 3, it will go all the way around until it reaches position 3 instead of taking one step backwards. For the actuator to calculate the direction which involves the least movement, the direction must be set to A (shortest route).

Modes available: Multiposition (3)

Examples

Command: **SM**<enter>

Returns: **SM** [0x0D] (*I* = current rotation direction)

Command: **SMF**<enter>

Sets the actuator to only move in the forward direction

SO[nn]

Sets the offset value of the first position to be any number from 1 – 96, where *nn* = 1 – 96.

This feature makes it possible to control more than one actuator with a single computer. The actuator's SO value can be set from "1" to "96", minus the current NP value (the number of positions the actuator is set to index). Once an SO value is set, that value is the first (or lowest) position an actuator will recognize. The factory SO setting is "1", so an actuator with an NP value of 10 responds to move commands for positions "1" to "10". If the SO value is changed to "10", the actuator will respond only to move commands for positions "10" through "19". For any setting of SO and NP, the lowest valid position will be the SO value and the highest valid position will be the SO value plus the NP value minus 1; i.e., the actuator will respond to commands for position SO through position {SO + NP - 1}. Refer to "Using the Offset Feature" on page 19.

Modes available: All (but used primarily in mode 3, multiposition)

Examples

Command: **SO**<enter>

Returns: **SO***nn* [0x0D] (*nn* = current offset value)

Command: **SO10**<enter>

Sets the offset value to 10. The valve will now start counting as if 10 = position 1

STAT

Returns (via the serial port) the following information,

CP = current position

AM = current mode

NP = number of ports (modes 1 and 2) or positions (mode 3) on the current valve

(See also **CP**, **AM**, and **NP** commands)

Modes available: All

Example

Command: **STAT**<enter>

Returns: Current status of the actuator

TM

Returns the amount of time, in milliseconds, required by the previous move

Modes available: All

Example

Command: **TM**<enter>

Returns: Number of milliseconds taken to move from the previous position to the current position